

CLAIMS

1. A method of adjusting an origin of an industrial robot, said method comprising:

providing an industrial robot which includes

5 a first member,

a positioning member arranged to be attached to the first member,

a second member arranged to rotate relatively to the first member, the second member having a contact point arranged to contact the positioning member, and

10 a first joint for coupling the first member with the second member;

displaying an indication for requesting to enabling the positioning member to contact the contact point;

15 rotating the second member at the first joint relatively to the first member while the positioning member can contact the contact point;

detecting whether or not the contact point of the second member contacts the positioning member; and

storing a position of the second member as an origin when
20 detecting that the contact point of the second member contacts the positioning member.

2. The method of claim 1, further comprising:

after said storing the position of the second member as the origin,
25 positioning the contact point of the second member at a predetermined position where the contact point does not contact the first member;

displaying an indication for disabling the positioning member to

contact the contact point; and

confirming whether or not the positioning member cannot contact the contact point.

5 3. The method of claim 2, wherein said confirming whether or not the positioning member cannot contact the contact point comprises rotating the second member at the first joint relatively to the first member.

4. The method of claim 1, further comprising:

10 displaying an indication for requesting to disable the positioning member to contact the contact point; and

positioning the contact point of the second member at a predetermined position by rotating the second member relatively to the first member while the positioning member cannot contact the contact point,

15 wherein said displaying the message for requesting to disable the positioning member to contact the contact point is executed before said positioning the contact point of the second member at a predetermined position.

20 5. The method of claim 1, wherein the industrial robot further includes a second joint, said method further comprising

selecting the first joint from the first joint and the second joint.

6. The method of claim 1, wherein the joint the industrial robot further
25 includes a motor for rotating the second member relatively to the first member, and

wherein said detecting whether or not the contact point of the

second member contacts the positioning member comprises detecting whether or not the contact point of the second member contacts the positioning member according to a current flowing in the motor.